INDEX TO VOLUME 7

Arkin, R. C. Navigational path planning for a vision-based mobile robot, 49–63

Artigue, F., Amirat, M. Y. and Pontnau, J. Isoelastic behavior of parallel robots, 323–325

Beiner, L. Combined time/location optimization of robotic motions with specified paths and velocity profiles, 309–314

Bodner, A. Adding flexibility to the links of a rigid-link dynamic model of an articulated robot, 165–168

Bone, G. M. and Elbestawi, M. A. Robotics force control for deburring using an active end effector, 303–308

Borovać, B., Vukobratović, M. and Stokić, D. Stability analysis of mechanisms having unpowered degrees of freedom, 349–357

Borovać, B., Vukobratović, M. and Surla, D. An approach to biped control synthesis, 231–241

Buchal, R. O. and Cherchas, D. B. An iterative method for generating kinematically feasible interference-free robot trajectories, 119–127

Cassar, J. P. and Vanheeghe, P. Specific computation of inverse kinematics in a robot off-line programming environment, 65–69

Chion, B. C. and Shahinpoor, M. Effect of joint stiffness on the dynamic stability of a one-link force-controlled manipulator, 339–342

Desoyer, K. and Lugner, P. Recursive formulation for the analytical or numerical application of the Gibbs–Appell method to the dynamics of robots, 343–347

Eghtedari, F. and Morgan, C. A novel tactile sensor for robot applications, 289–295

Gupta, K. C. and Singh, V. K. A numerical algorithm for solving robot inverse kinematics, 159–164

Hardy, N. W., Barnes, D. P. and Lee, M. H. Automatic diagnosis of task faults in flexible manufacturing systems, 25–35

Ho, C. Y. and Sriwattanathamma, J. Symbolically automated direct kinematic equations solver for robotic manipulators, 243–254

Jacak, W. Strategies of searching for collision-free manipulator motions: automata theory approach, 129–138

Jarka, R. E., Sabn, Z. A., Adams, S. K., Liang, E., Barnett, M., Rodriguez, R. J. and Husseiny, A. A. Design of an advanced robotic vechicle evaluation laboratory, 281–287

Jumarie, G. Two stage sliding controller for manipulators with time-varying inertia links, 255–261

Jutard, A., Redarce, T., Fakri, A. and Betemps, M. Geometric model of the DCR-LAI compliant device, 151–157

Kanarachos, A., Sfantsikopoulos, M. and Vionis, P. A splines-based control method for robot manipulation, 213–221

Kazerooni, H. Statically balanced direct drive manipulator, 143–149

Kazerooni, H. Compliance control and stability analysis of cooperating robot manipulators, 191–198

Kemal Ciliz, M. and Can Isik. Fuzzy rule-based motion controller for an autonomous mobile robot, 37–42

Kyu Won Jeong and Hyung Suck Cho. Development of a pneumatic vibratory wrist for robotic assembly, 9-16

Lenarčič, J. R&D at the Robotics Laboratory of The Jožef Stefan Institute (Yugoslavia), 113–117

Lim, T. G., Cho, H. S. and Chung, W. K. A parameter identification method for robot dynamic models using a balancing mechanism, 327–337

Nicholls, H. R., Rowland, J. J. and Sharp, K. A. I. Virtual devices and intelligent gripper control in robotics, 199–204

Ozaki, H., Shimadzu, T. and Mohri, A. Collision-free path generation for a mobile robot by an artificial transformation of obstacle spaces, 139–142

Parnis, P. J. and Drazan, P. J. Recognition of unreliable ultrasonic range data in a robotic environment, 223–229

Pu, J. and Weston, R. H. A new generation of pneumatic servos for industrial robots, 17–23

Rock, S. T. Developing robot programming languages using an existing language as a base—A viewpoint, 71–77

Shin, Y. and Bien, Z. Collision-free trajectory planning for two robot arms, 205–212

Troch, I. Time-suboptimal quasi-continuous path generation for industrial robots, 297–302

Verdier, M., Rouff, M. and Fontaine, J. G. Nonlinear control robot: A phenomenological approach to linearization by static feedback, 315–321

Weisbin, C. R., Hamel, W. R., Kuban, D. P., Meacham, S. A. and Pin, F. G. The Robotics and Intelligent Systems Program (RISP) at The Oak Ridge National Laboratory, 101–111

Yamamoto, M. and Mohn, A. Planning of quasi-minimum time trajectories for robot manipulators (Generation of a bang–bang control), 43–47